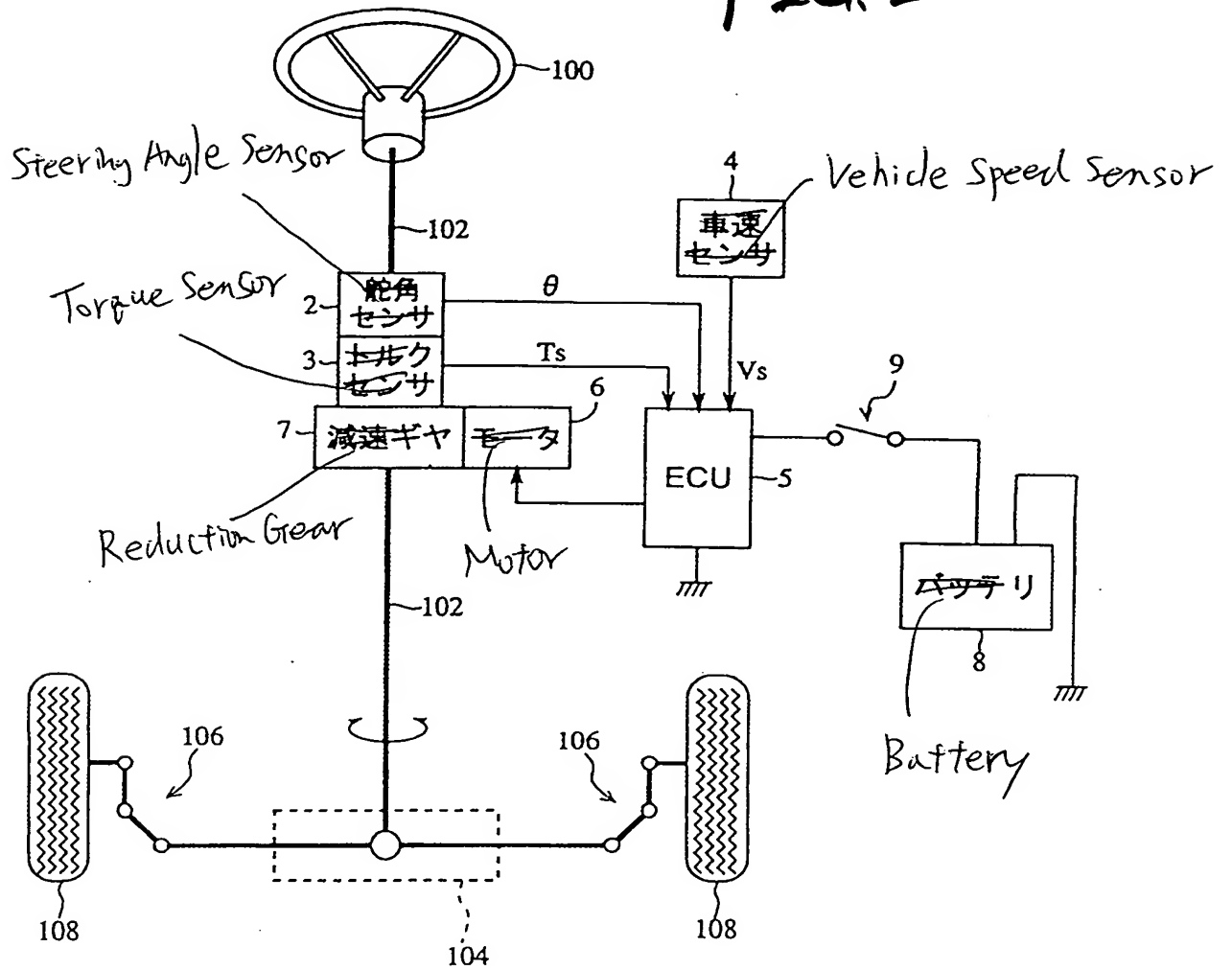


FIG. 1



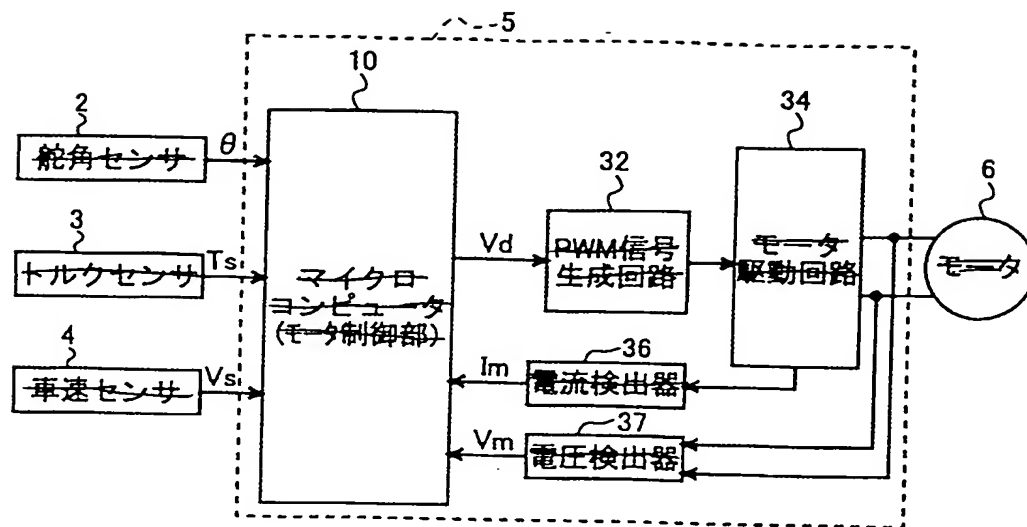


FIG. 2

2 ... Steering angle sensor

3 ... Torque sensor

4 ... Vehicle speed sensor

6 ... Motor

10 Microcomputer (Motor control section)

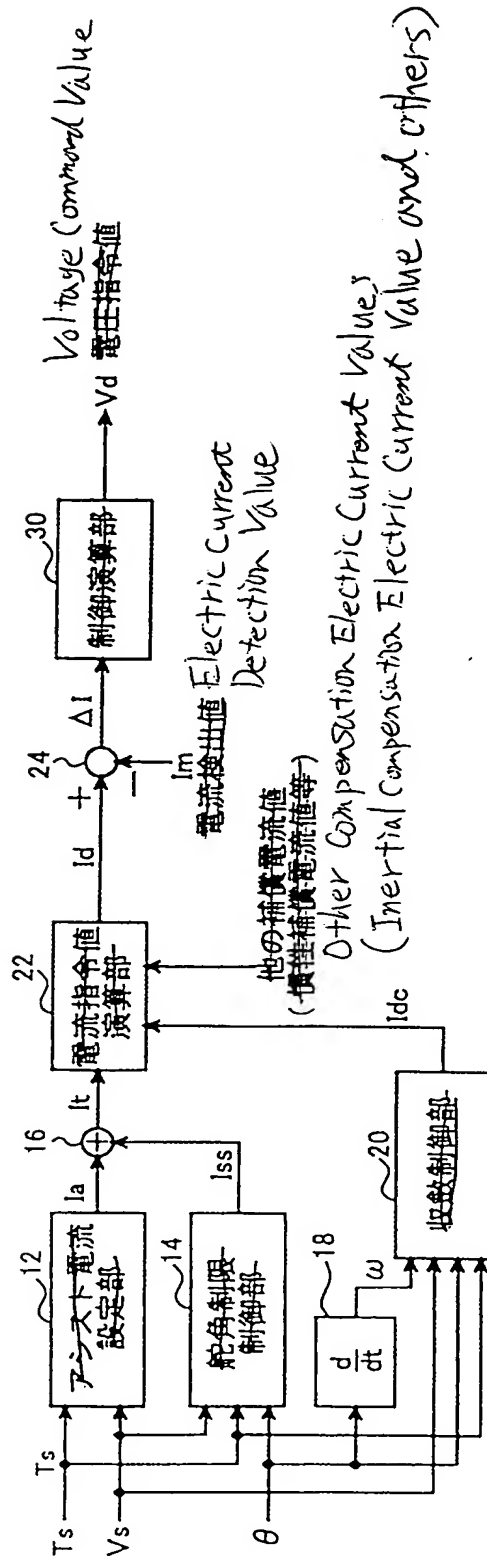
32 ... PWM signal generating circuit

34 ... Motor drive circuit

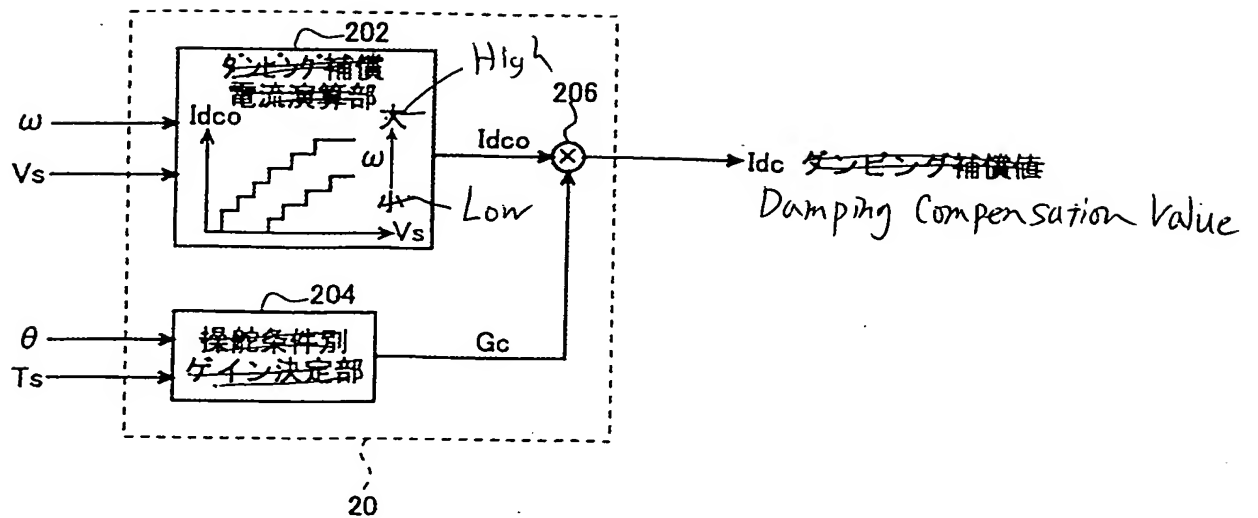
36 ... Electric current detector

37 Voltage detector

# FIG. 3



- 12 Assisting electric current setting section
- 14 Steering angle restricting control section
- 20 Convergence control section
- 22 Electric current command value calculating section
- 30 Control calculating section



202 Damping compensation electric current calculating section

204 Gain deciding section for each steering condition

FIG. 4

Fig. 5A

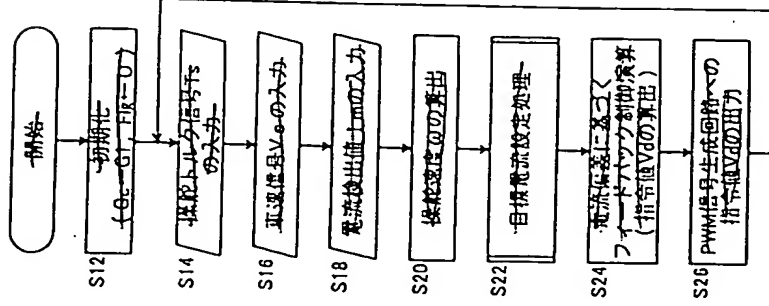


Fig. 5B

S22

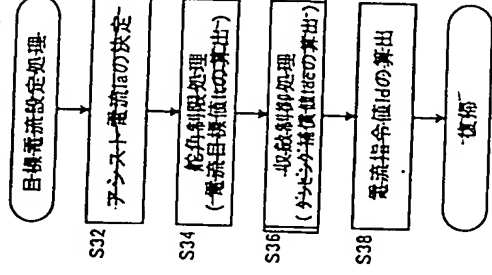


Fig. 5A

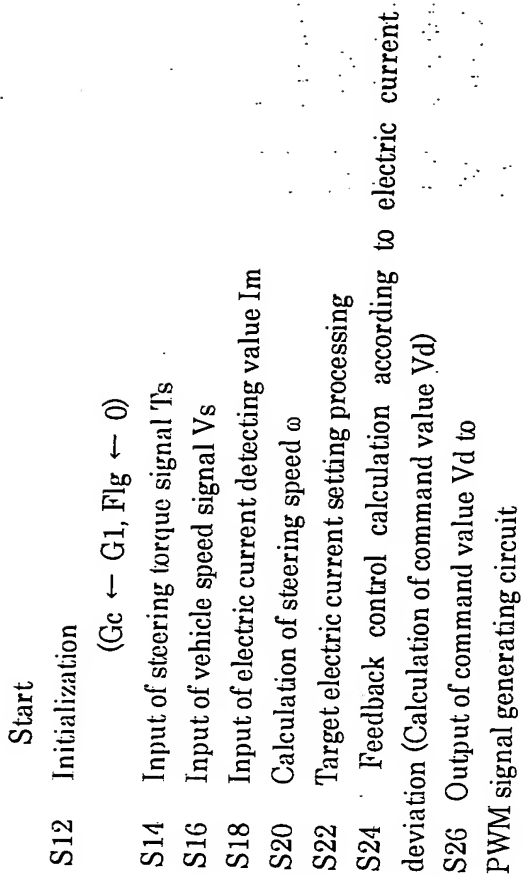


Fig. 5B

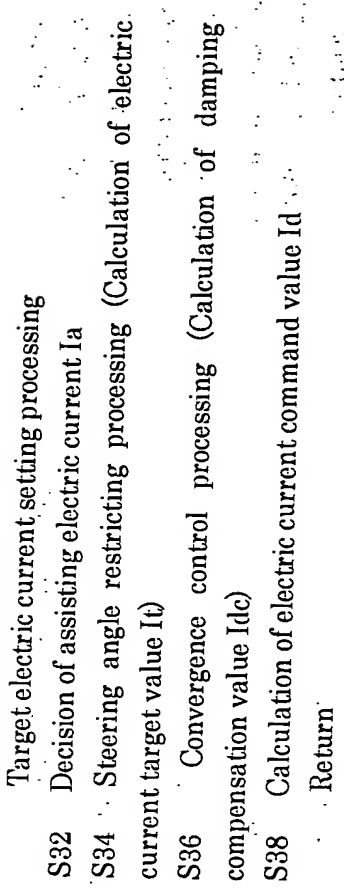


Fig. 6A

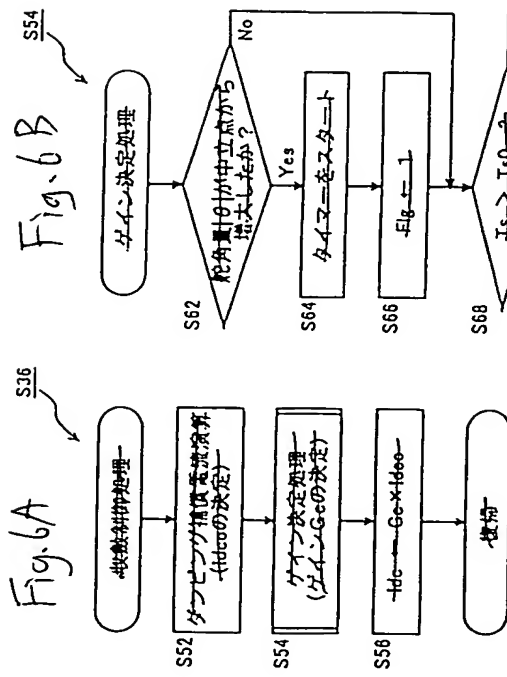


Fig. 6A

- Convergence control processing
- S52 Damping compensation electric current calculation (Decision of Idco)
- S54 Gain deciding processing (Decision of gain Gc)
- S56 Ids ← Gc × Idco
- Return

Fig. 6B

- Gain-deciding processing
- S62 Has steering angle quantity |θ| increased from neutral point?
- S64 Start timer
- S66 Flg ← 1
- S68 Ts > Tm0?
- S70 Flg ← 0
- S72 Has steering angle quantity |θ| decreased?
- S74 Timer value Tm ≤ Tm0?
- S76 Flg = 1?
- S78 Gc ← G2
- S80 Gc ← G1
- Return

